



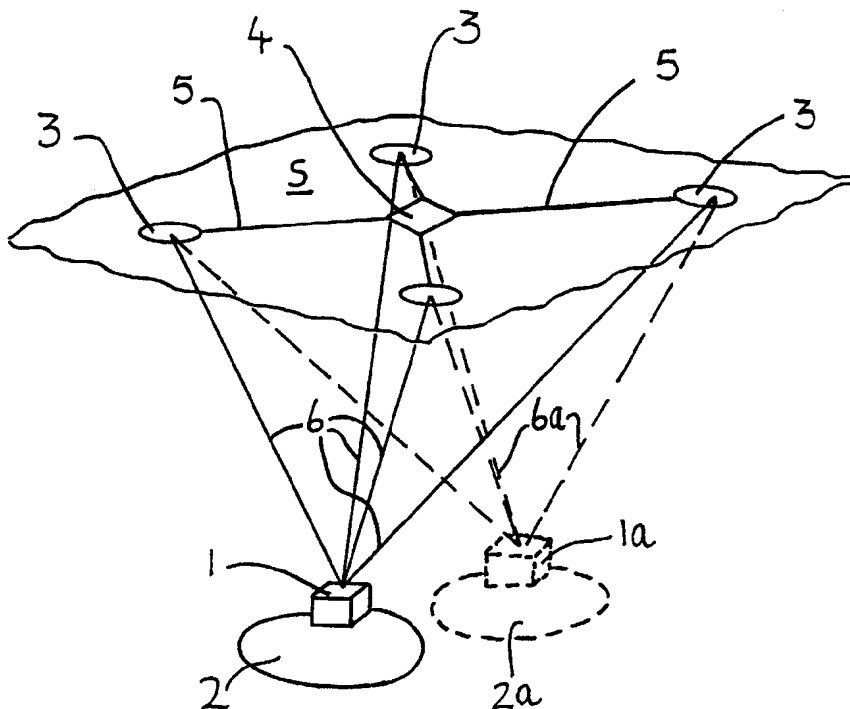
## INTERNATIONAL APPLICATION PUBLISHED UNDER THE PATENT COOPERATION TREATY (PCT)

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(54) Title: SYSTEMS AND METHODS FOR LOCATING SUBSURFACE OBJECTS

## (57) Abstract

A subsurface object location apparatus for determining the position of an object (2) located below a surface (S) such as a land surface, the surface of the sea or a seabed. A subsurface unit (1) having transmitter means for transmitting inductive signals is mounted on the object (2). A plurality of surface units (3) are disposed at spaced locations at the surface (S). Each surface unit (3) has receiver means arranged for receiving the inductive signals. Processing means (4) are provided for determining the location of the object (2) using time difference of arrival techniques in respect of the signals received at the surface units. Cyclic correlation is used in determining the times of reception of signals at the surface units.



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"Systems and Methods for Locating Subsurface Objects"

This invention relates to systems and methods for locating subsurface objects.

5           In this specification the expression subsurface object includes objects located below a land surface, below the surface of a body of water and below a seabed.

          In a number of circumstances it is desirable to  
10   be able to determine the position of a subsurface object. Examples of such circumstances include the determination of the position of an underwater vehicle which, for example, is being used to inspect a pipeline and the determination of the position of a  
15   drilling tool during the directional drilling of an oil well.

          Existing systems for determining the position of subsurface objects have disadvantages.

          It is an object of the present invention to  
20   provide a system for determining the position of subsurface objects which alleviates at least some of the problems associated with existing systems.

          According to one aspect of the present invention there is provided a subsurface object location system  
25   for determining the position of an object located

below a surface, comprising a subsurface unit having transmitter means and being arranged to be mounted on the object, a plurality of surface units having receiver means and being arranged to be disposed at spaced locations at the surface, and processing means for determining the times of reception at the plurality of receiver means, of a signal transmitted from the transmitter means and determining the location of the object on the basis of the times of reception.

According to another aspect of the present invention there is provided a method for determining the position of an object located below a surface, comprising the steps of:

- 15 mounting a subsurface unit having transmitter means on the object;
- disposing a plurality of surface units having receiver means at spaced locations at the surface;
- using the transmitter means to transmit a signal from the object;
- 20 determining the reception times of the signal at each of the plurality of receiver means; and
- determining the location of the object on the basis of the times of reception.
- 25 Preferably the processing means is arranged to

compare the times of reception of the signals and to determine the location of the object on the basis of said comparison.

Said method preferably includes the steps of  
5 comparing the times of reception of the signals and determining the location of the object on the basis of said comparison.

Preferably at least three surface units are provided, more preferably still at least four surface  
10 units are provided.

In general there are four unknowns, namely three spatial co-ordinates and time. Not all of these unknowns need be determined using the reception times of the signals. For example depth may be determined  
15 by pressure sensors or other means. Further, or alternatively, a time reference may be provided at the transmitter. If all four unknowns have to be determined by time of reception, at least four surface units are required.

20 Subsurface, especially underwater, object location systems may use acoustic links. The use of acoustic links has disadvantages at least in part because of the multipath dispersion which occurs. Preferably the transmitter and receiver means are  
25 arranged respectively to transmit and receive

inductive signals and in use the signals transmitted by the transmitter means are inductive signals. The use of inductive signals is advantageous because any multipath dispersion effects are minimized and the  
5 attenuation of the magnetic vector as electromagnetic radiation passes through water and many types of lithology is significantly lower than that of the electric vector.

Preferably a central unit is provided which is  
10 connected by a communication link to each of the surface units. The central unit may comprise a surface unit. Each surface unit may be arranged to relay signals to the central unit via the respective link. In some embodiments each surface unit is connected to  
15 the central unit by a high quality link having known characteristics. The central unit may be arranged to compare the time of reception by each surface unit, of signals transmitted from the subsurface unit. The central unit may be arranged to determine the time of  
20 reception of the signals by each surface unit on the basis of the time of reception of a relay signal from each surface unit and the known characteristics of the high quality links.

Each high quality link preferably has a high  
25 bandwidth. A high quality link is a link which has

characteristics which can be determined accurately enough and remain within such tolerances that the time delay introduced by each link can be determined to an accuracy which allows the position of a subsurface object to be determined to the accuracy required in the particular circumstances. Such embodiments have the advantage that no master clock is required.

In other embodiments each surface unit is arranged to determine the time of reception of a signal from the subsurface unit by reference to a master clock and to relay an appropriate signal via the respective link to the central unit. The central unit may be arranged to determine the position of the subsurface object on the basis of the signals received from the surface units. The master clock may be that available via GPS. Such embodiments have the advantage that high quality links are not required.

The signals used to determine the position of the object may also be used to carry data. The subsurface unit may comprise receiver means for receiving signals from the surface. One or more surface unit and/or the central unit may comprise transmitter means for transmitting signals to the subsurface unit.

The object location system may be arranged to operate where the signals pass through earth/land

and/or seawater.

The subsurface object location system may be a subsea object location system.

Embodiments of the present invention will now be described, by way of example only, with reference to the accompanying drawings in which:

Figure 1 schematically shows a subsurface objection location system;

Figure 2 shows a plot to aid in understanding of a cyclic correlation technique.

Figure 1 schematically shows a subsurface object location system which comprises a subsurface unit 1 mounted on an object 2 the position of which is to be monitored, four surface units 3 and a central unit 4. Each of the surface units 3 and the central unit 4 are provided at a surface S which might, for example, be a land surface, the surface of a body of water or a sea bed. The object 2, which might be an underwater vehicle or a drilling tool, is typically able to move in three dimensions through a liquid and/or solid environment below the surface S.

Typically the object location system will be used for location over relatively large distances, say in the order of hundreds or even thousands of meters.

The subsurface unit 1 comprises a inductive



signal transmitter (not shown) and each of the surface units 3 includes an inductive signal receiver (not shown) which is suitable for receiving inductive signals transmitted from the subsurface unit 1. The central unit comprises processing means (not shown) for determining the position of the object 2. Each of the surface units 3 is connected by a high quality communications link 5 to the central unit 4. The communications links 5 are used to relay signals received by the surface units 3 to the central unit 4. The links are arranged to have high bandwidth and to have substantially constant characteristics. The characteristics of each link 5 are accurately determined and stored at the central unit so that the effect, primarily the delay, caused by transmission of a signal over each link can be determined by the central unit.

In operation, under predetermined conditions, the subsurface unit 1 transmits inductive signals which travel through the environment below the surface S. The transmission of signals may be continuous, periodic, triggered automatically or occur at the instruction of a user.

Typically the inductive signals will have a frequency in the very low frequency (vlf) range or low

frequency (1f) range. These frequencies are chosen because they propagate reasonably well through earth and sea water. A frequency of the order of 70 KHz can be effective and this leads to a wavelength in the  
5 order of 4 to 4.5 km. In some circumstances it is desirable to select the frequency of the signal such that the distance between the object 2 and surface units 3 is less than the wavelength of the signal.

The paths of an inductive signal from the  
10 subsurface unit 1 to the surface units 3, when the object 2 is in a first position, are shown by full lines 6 and the paths of an inductive signal from the subsurface unit 1a to the surface units 3, when the object 2a is in a second position are shown by dotted  
15 lines 6a.

It can be seen that the signal paths 6 when the object 2 is in the first position are of different lengths and different relative lengths than the signal paths 6a when the object 2a is in the second position.  
20 Provided that the positions of each of the surface units 3 are known then the position of the subsurface unit 1 and hence the object 2 can be determined by comparing the times at which a signal transmitted by the subsurface unit arrives at each of the surface  
25 units 3. This can be achieved by using time difference

of arrival techniques such as are described in US Patent No. 4,888,593.

Conventional TDOA methods require high bandwidth signal channels, bandwidth being inversely related to resolution required. In the present system, as  
5 mentioned above, inductive signals having relatively long wavelengths are used. This means that it is difficult or impossible to provide useful location data by making single measurements to determine the  
10 time of arrival of a signal. Accuracy may be improved by statistical means by combining multiple measurements rather than merely noting the arrival time of say, a particular peak. It has been realised by the applicants that one way to help reduce  
15 bandwidth requirements and improve accuracy in the present system is to use cyclic cross correlation techniques such as those described in US Patent No. 4,888,593.

A currently preferred technique for determining  
20 the time of reception of the inductive signals uses cyclic correlation between the received signal and a synthesised signal. In this case a continuous, generally sinusoidal, signal is transmitted by the transmitting means (not shown) and received at each of  
25 the surface units 3. The frequency of the signal is

such that the wavelength of the signal is greater the distance between the object 2 and the surface units 3. This ensures that the phase difference between the signal at the object 2 and each surface unit 3 is less than  $360^\circ$ . Similarly the phase differences between the signals received at each of the surface units 3 will be less than  $360^\circ$ . This ensures that the distances calculated do not suffer from inaccuracies due to ambiguous phase differences.

10        In the technique, a cyclic correlation is performed between a selected portion of the signal received at each of the surface units and a synthesised signal having the same general form as the expected received signal. The timing/phase of the synthesised signal is changed until the correlation reaches a maximum, indicating that the received signal and synthesised signal are in phase. The time of a chosen reference point (for example, a particular zero crossing) on the synthesised signal can then be taken as the time of reception of the respective received signal. This process is repeated for all of the other received signals using the same reference point in the synthesised signal as the basis for time of reception. The number of cycles of the received signal used in calculating the correlation is a matter of design

choice and depends on the resolution/speed desired and the amount of processing power to be used.

Figure 2 is a plot to aid in understanding of the above technique and schematically shows an (idealised) signal R as received at one of the surface units 3 with a time of reception  $t_r$  and a synthesised signal Y. The received signal R and synthesised signal Y are shown out of phase, a reference point P of the synthesised signal being coincident with zero time. In the method, as described above, the synthesised signal Y is shifted forward in time, so moving to the right on the plot, until the correlation function is maximised as the two signals R,Y coincide. In this state, the reference point P will coincide with the time of reception  $t_r$ , so that the value of  $t_r$  can be determined. It should be noted that zero time mentioned above may not be the time at which the signal left the transmitter. Further, although the time of reception  $t_r$  may be measured in absolute time, it is only necessary to be able to compare the times of reception at the various different surface units.

In the present embodiment when an appropriate inductive signal is received at one of the surface units 3, a relay signal is generated by that surface unit 3 and sent to the central unit 4 via the

respective high quality link 5. When the same inductive signal from the subsurface unit 1 is received by the other surface units 3, respective relay signals are sent over the respective links 5 to the central unit 4. The central unit 4 is arranged to monitor the time of arrival of such signals and, by subtracting the delay caused by relaying the signal over the respective link 5, is able to determine the time of arrival of the inductive signal at each of the surface units 3. Hence by using the time difference of arrival techniques mentioned above, the central unit 5 can determine the position of the object 2.

In alternative embodiments rather than providing high quality links and performing a direct comparison at the central unit 4, each surface unit 3 may be arranged to determine the time of reception of an inductive signal by referring to a master clock provided by GPS. Each surface unit 3 can then send details of the time of arrival of the inductive signal to the central unit 4 via a standard communication link. The position of the object 2 may then be determined by the central unit 4 using time difference of arrival techniques as described above.

The signal transmitted for object location purposes may also be used to transmit data. It will be

seen that the time of reception determining technique outlined above is unaffected if the signal is subject to say, amplitude modulation, in order to carry data. The transmitted data may serve many purposes and  
5 useful data rates say in the order of 5 kbits/second may be achieved. When the object being located is a survey vehicle, the data may comprise measurements taken by the survey vehicle such as temperature and pressure. The data may also be used to avoid any  
10 problems of ambiguous phase difference in a different way to that mentioned above. Data may also be transmitted from the surface to the subsurface object 2.

It will be appreciated that the precise positioning of the surface units 3 and central unit 4  
15 is not critical, they merely need to be positioned in some convenient known location. Thus these units 3,4 may, for example, be suspended below a surface or buried in the ground. When so positioned, the units are still considered to be located at a surface for  
20 the purposes of this specification. In some circumstances, not having all of the surface units 3 in the same plane may assist in the location of the subsurface object.

For the avoidance of doubt, it is mentioned that  
25 in this application the term inductive signal is used

to mean a magnetic rather than electric signal. In particular it is the magnetic vector of a propagating electromagnetic wave which is of concern and that is generated by the transmitter and received by the  
5 receivers.



## CLAIMS:

1. Subsurface object location apparatus for determining the position of an object located below a surface, comprising:

5 a subsurface unit having transmitter means and being arranged to be mounted on an object the location of which is to be monitored;

a plurality of surface units disposed at spaced locations at the surface and each having receiver  
10 means; and

processing means arranged for determining the times of reception and/or relative times of reception at the plurality of receiver means, of a signal transmitted from the transmitter means and determining  
15 the location of the object on the basis of the times and/or relative times of reception, characterised in that the transmitter and receiver means are arranged respectively to transmit and receive inductive signals.

20

2. Apparatus according to Claim 1 in which the processing means is arranged for taking a plurality of measurements of the signal received at each surface unit in order to determine the time of reception or  
25 relative time of reception of the signal at each

surface unit.

3. Apparatus according to Claim 1 or Claim 2 in which the processing means is arranged for performing  
5 a cyclic correlation to determine times of reception or relative times of reception of the signal at each surface unit.

4. Apparatus according to Claim 3 in which the  
10 cyclic correlation is performed between the received signal and a synthesised signal.

5. Apparatus according to any one of Claims 1 to 4 in which the processing means is arranged to compare  
15 the times of reception of the signal and to determine the location of the object on the basis of said comparison.

6. Apparatus according to any preceding claim  
20 further comprising a central unit which is connected by a communication link to each of the surface units.

7. Apparatus according to Claim 6 in which each communication link is a high quality link having known  
25 characteristics and the central unit is arranged to

compare the time of reception by each surface unit, of  
a signal transmitted from the subsurface unit on the  
basis of the time of reception, at the central unit,  
of a relay signal passed from each surface unit and  
5 the known characteristics of the high quality links.

8. Apparatus according to Claim 6 in which each  
surface unit is arranged to determine the time of  
reception of a signal from the subsurface unit by  
10 reference to a master clock and to relay a signal  
indicating the determined time of reception, via the  
respective link, to the central unit.

9. A method for determining the position of an  
15 object located below a surface, comprising the steps  
of:

mounting a subsurface unit having transmitter  
means on the object;

20 disposing a plurality of surface units having  
receiver means at spaced locations at the surface;

using the transmitter means to transmit an  
inductive signal from the object;

determining the times or relative times at which  
the inductive signal is received at each of the  
25 plurality of receiver means; and

determining the location of the object on the basis of the times or relative times of reception.

10. A method according to Claim 9 comprising the step  
5 of taking multiple measurements of the signal received at each surface unit in order to determine the time of reception or relative time of reception of the signal at each surface unit.
- 10 11. A method according to Claim 9 or Claim 10 comprising the step of performing a cyclic correlation to determine times of reception or relative times of reception of the signal at each surface unit.
- 15 12. A method according to Claim 11 in which the cyclic correlation is performed between the received signal and a synthesised signal.
13. A method according to any one of Claims 9 to 12  
20 which includes the steps of comparing the times of reception of the signal and determining the location of the object on the basis of said comparison.
14. A method according to any one of Claims 9 to 12  
25 comprising the step of connecting each of the surface

units via a communication link to a central unit.

15. A method according to Claim 14 in which each communication link is a high quality link having known characteristics and the method comprises the steps of,  
5 at the central unit, comparing the time of reception by each surface unit, of the signal transmitted from the subsurface unit on the basis of the time of reception, at the central unit, of a relay signal  
10 passed from each surface unit and the known characteristics of the high quality links.

16. A method according to Claim 14 comprising the steps of, at each surface unit, determining the time  
15 of reception of the signal from the subsurface unit at the respective surface unit by reference to a master clock and relaying a signal indicating the time of reception via the respective link to the central unit.

20 17. A method or apparatus according to any preceding claim in which four surface units are provided.

18. A method or apparatus according to any preceding claim in which the signals used in determining the  
25 position of the object are also used to carry data.

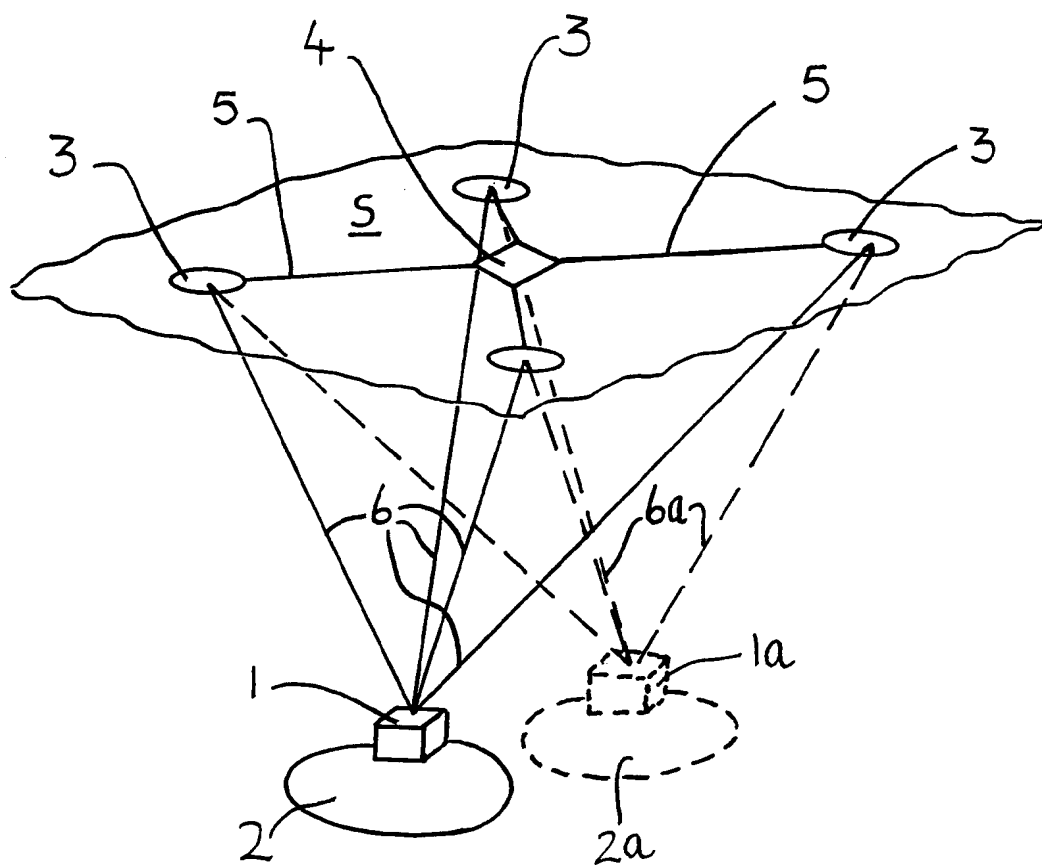


FIG. 1

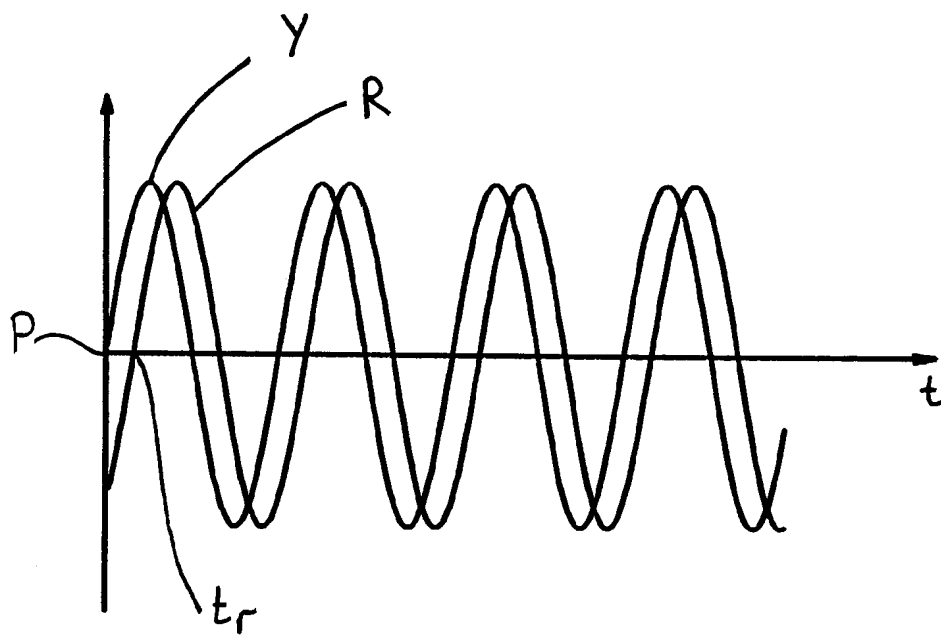


FIG. 2

# INTERNATIONAL SEARCH REPORT

International Application No

PCT/GB 00/01505

## A. CLASSIFICATION OF SUBJECT MATTER

IPC 7 G01S5/06 G01V3/12

According to International Patent Classification (IPC) or to both national classification and IPC

## B. FIELDS SEARCHED

Minimum documentation searched (classification system followed by classification symbols)

IPC 7 G01S A63B G01V

Documentation searched other than minimum documentation to the extent that such documents are included in the fields searched

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## C. DOCUMENTS CONSIDERED TO BE RELEVANT

Category *	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
Y	FR 2 720 840 A (BARDOT OLIVIER ;BARDOT MARINA) 8 December 1995 (1995-12-08)  abstract page 6, line 25 - line 29 page 17, line 16 -page 18, line 30 ---	1-3,5,6, 8-11,13, 14,16-18
Y	US 4 961 143 A (TAKAHASHI KOZO ET AL) 2 October 1990 (1990-10-02)  abstract column 2, line 48 -column 4, line 49 column 5, line 67 -column 6, line 2 column 7, line 22 - line 35 ---  -/--	1-3,5,6, 8-11,13, 14,16-18

☒ Further documents are listed in the continuation of box C.

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Date of the actual completion of the international search

3 August 2000

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# INTERNATIONAL SEARCH REPORT

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## C.(Continuation) DOCUMENTS CONSIDERED TO BE RELEVANT

Category	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
A	US 4 888 593 A (FRIEDMAN JOSEPH S ET AL) 19 December 1989 (1989-12-19) cited in the application abstract ----	1,3,4,9, 11,12
A	US 5 374 936 A (FENG JUN) 20 December 1994 (1994-12-20) abstract column 1, line 23 -column 2, line 33 ----	1,6-9, 14-16
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# INTERNATIONAL SEARCH REPORT

Information on patent family members

International Application No

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